



# Crew integration & Automation Testbed and Robotic Follower Programs

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Bruce Brendle

*Team Leader, Crew Aiding & Robotics Technology*

Email: [brendleb@tacom.army.mil](mailto:brendleb@tacom.army.mil)  
(810) 574-5798 / DSN 786-5798  
Fax (810) 574-8684

U.S. Army Tank-Automotive RD&E Center (TARDEC)  
Vetronics Technology Area  
(AMSTA-TR-R, Mailstop 264)  
Warren, MI 48397-5000

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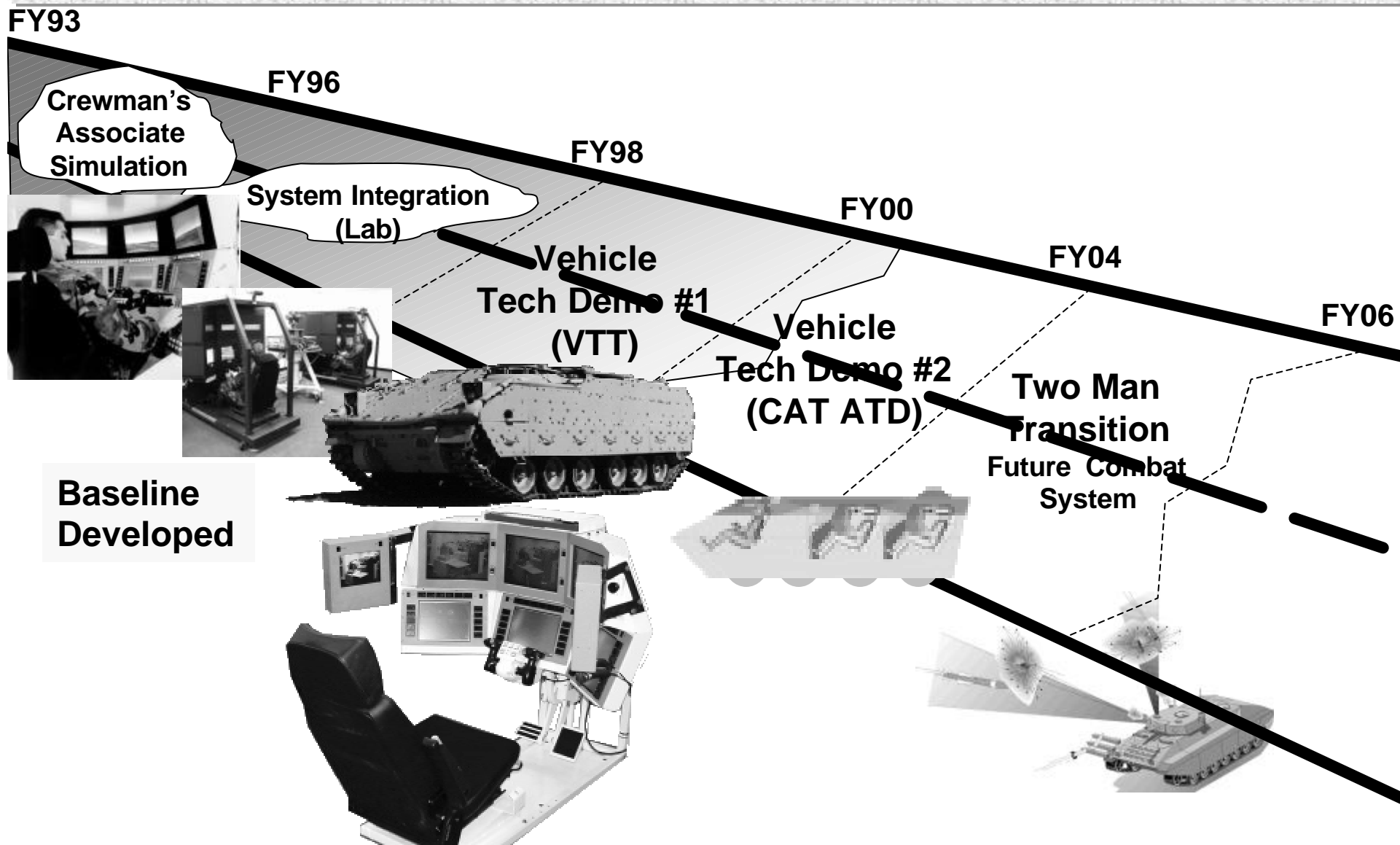
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Tank-automotive & Armaments  
COMmand



# TARDEC Crew Reduction Efforts



**“Evolving Technologies for Reduced Crew Operation”**



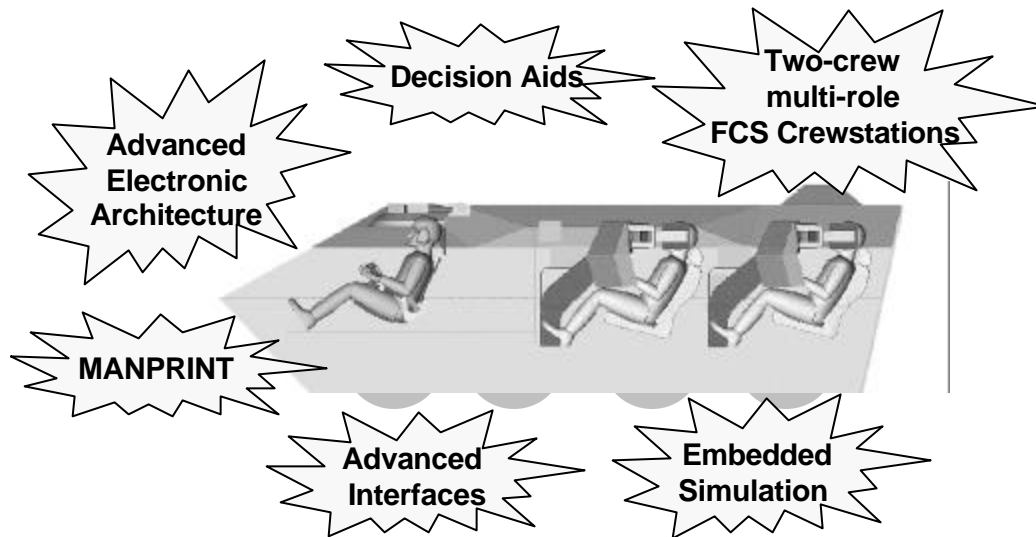
# Crew integration and Automation Testbed



- Objectives:
  - ▶ Demonstrate the crew interfaces, automation, and integration technologies required to operate and support future combat vehicles.
  - ▶ Demonstrate crew stations enabling two-crew operation of multi-mission capable, C-130 transportable systems required for the objective force of the Army.
- Status:
  - ▶ In Year #2 of 4-Year ATD Program
  - ▶ Active Crew Task Analysis IPT between MMBL, ARL and TARDEC
  - ▶ Active Architecture IPT with STO/ATD Managers
  - ▶ SMI Working Group Approved with Future Combat Systems



# Crew integration and Automation Testbed



*Concept Vehicle Shown with Onboard Safety Driver*

**Demonstrate the crew interfaces, automation, and integration technologies required to operate and support Future Combat Systems**

## Pacing Technologies:

Decision Aids

Soldier-Machine Interface

Embedded Simulation

Electronics Architecture

## Warfighter Payoffs:

- Enhanced performance, and survivability of the crew.
- Potential for reduced crew size (smaller, more transportable vehicles with lower logistics).
- Mission rehearsal capability



## CAT ATD Exit Criteria

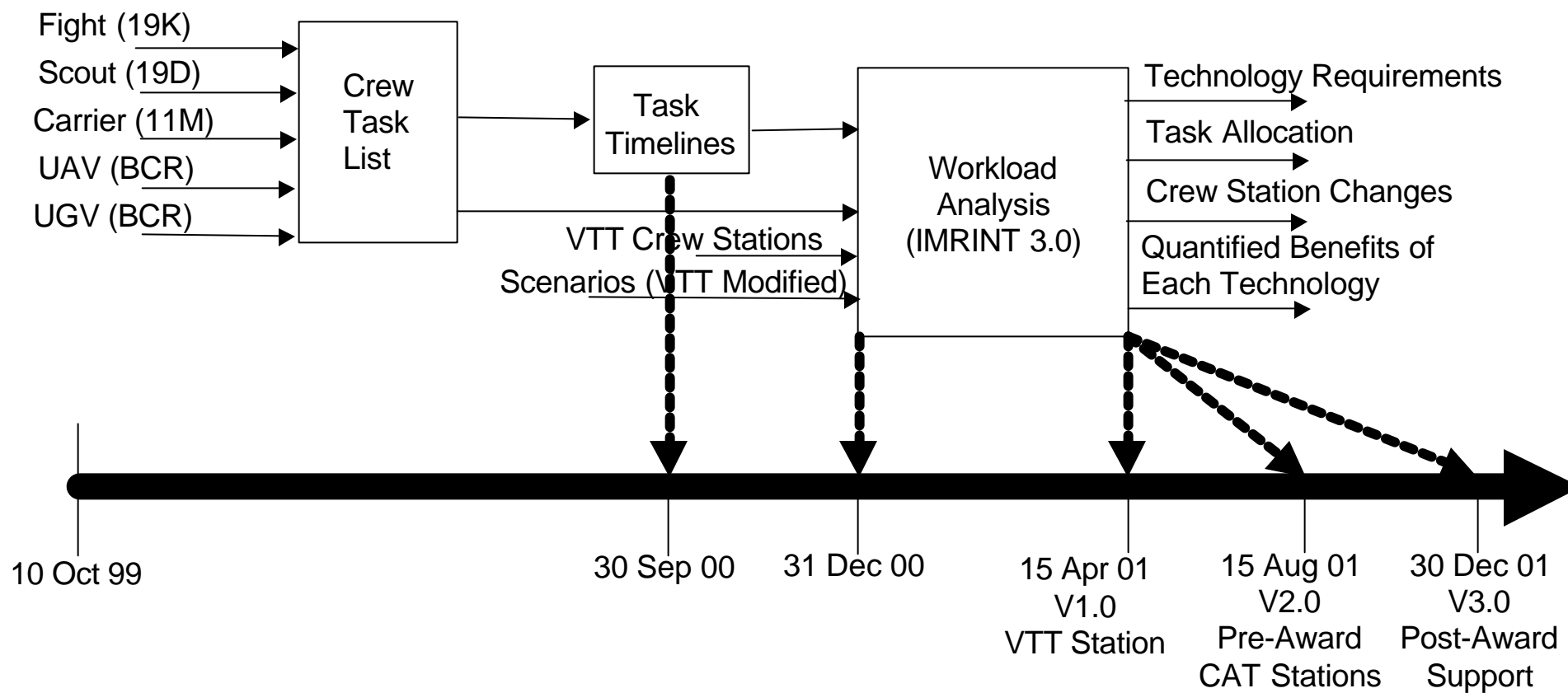


- Increase crew task efficiency, or reduce the number of crew personnel.
  - ▶ Cover 100% of fight (19K), scout (19D), & carrier (11M) crew tasks with additional tasks of controlling UAV's and UGV's performed with two crew members.
- In-Vehicle crew training capability.
  - ▶ Provide mixed, live-virtual simulation of vehicle in training exercises
- Increase software reuse.
  - ▶ Package 500K SLOC for reuse through APIs
- Increase architecture performance.
  - ▶ Provide 1000 Hz control loop for critical real-time tasks



# CAT Workload IPT

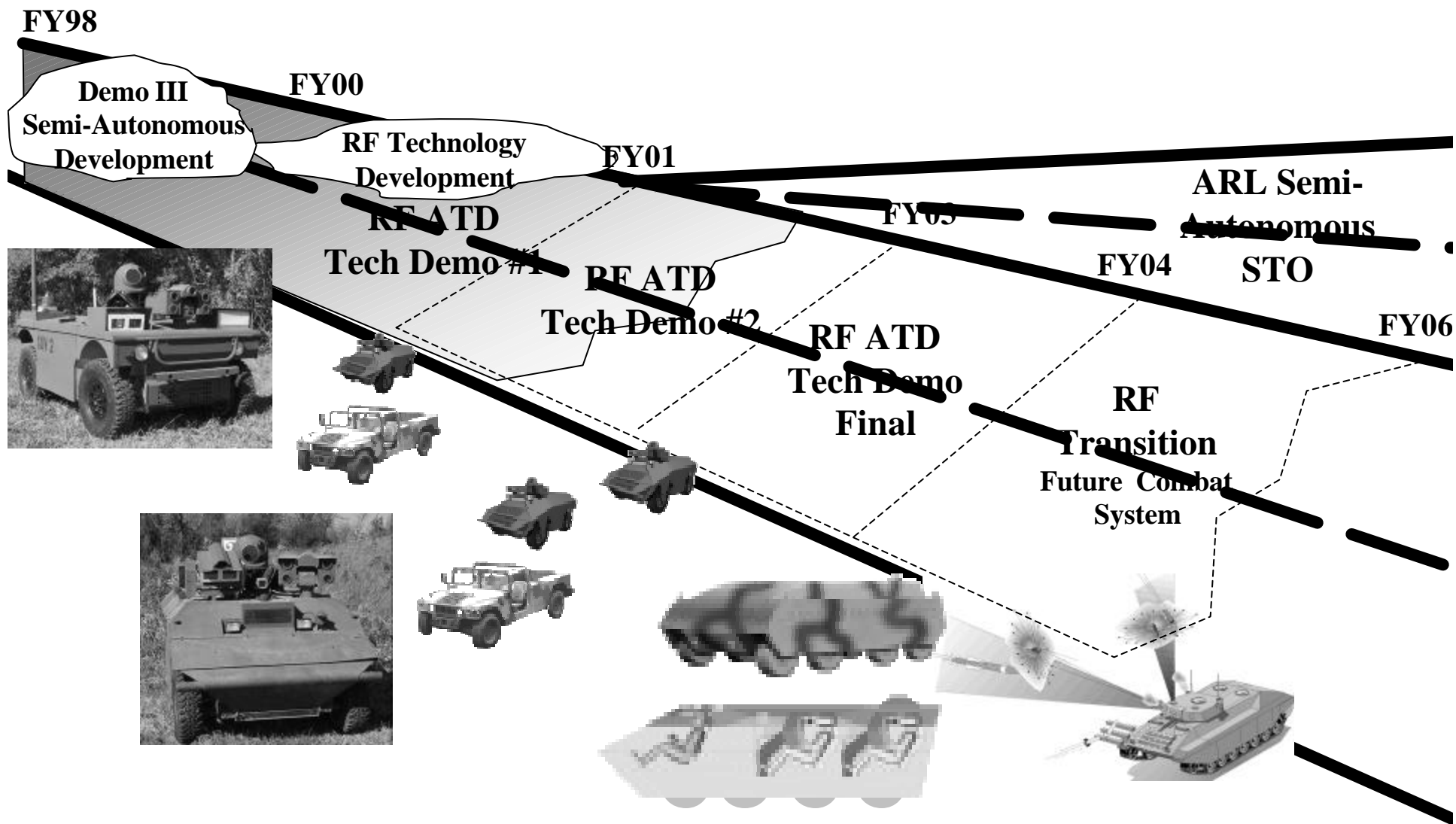
## Process and Product Schedule



UAV - Unmanned Arial Vehicle  
UGV - Unmanned Ground Vehicle



# Robotic Follower (RF) Evolution





# Robotic Follower ATD



- Objectives:
  - ▶ Develop, integrate and demonstrate the technology required to achieve unmanned follower capabilities for future land combat vehicles.
  - ▶ Maturation & demonstration of robotics technology required for early insertion into Future Combat Systems.
- Status:
  - ▶ In Year #1 of 5-Year ATD Program
  - ▶ Cooperative Program with Army Research Laboratory
  - ▶ Active Architecture IPT with STO/ATD Managers
  - ▶ Customer: TRADOC System Manager for Future Combat Systems





# Robotic Follower ATD



Ruck Carrier



Supply Platoon



Rear Security



NLOS/BLOS Fire

***Mature & Demonstrate Robotics  
Technology Required for Early  
Insertion into FCS***

## Pacing Technologies:

Semiautonomous  
Perception

Soldier-Robot  
Interface

Intelligent Situational  
Behavior

Leader-Follower  
Technology

## Solution Approach

- Manned leader “proofs” path to reduce perception & intelligence requirements
- Rapidly mature & integrate perception technology to enable higher speed & enhanced decision making capabilities
- Successively demonstrate maturing capability for FCS



# Robotic Follower Exit Criteria



Metric		Speed on Primary Road - (kph)	Speed X- Country - (kph)	Range - (km)	Max Time Delay - (hrs)	Separation - (m)	Obstacle Detection - (m)
Definition		Sustained speed on paved or improved road with firm base. Followers to stay in proper lane starting in 2003.	Open & rolling, highly trafficable for equivalent manned system.	Distance follower can travel using onboard intelligence.	Time between lead vehicle and follower vehicles crossing same piece of terrain	Distance between the lead and following vehicles, dependent on communication range and latency.	Size of non-engineered or camouflaged obstacles system can detect.
Current (Demo IIIb)		30	15	160	1	Min: 50 Max: 500	Positive: .5 Negative: 1x2x2
April, 2003 <sup>1</sup> (XUV chassis)		55	30	160	12	Min: 20 Max: 2 km	Positive: .3 Negative: 1x2x2
END ATD	Minimum	65	30	160	24	Min: 10 Max: 5 km	Positive: .3 Negative: 1x2x2
	Goal	100	65	750	24	Min: 1 Max: 200 km	Positive: .3 Negative: 1x1x1

<sup>1</sup> Difference between achieved performance in 2003 and End ATD will be demonstrated via modeling & simulation.



# Robotic Follower

## *Development and Test Environment*

